Computer Vision using Ruby and libJIT

WEDEKIND, Jan

Hornets Eye

RubyConf 2009

Computer Vision using Ruby and libJIT

Jan Wedekind

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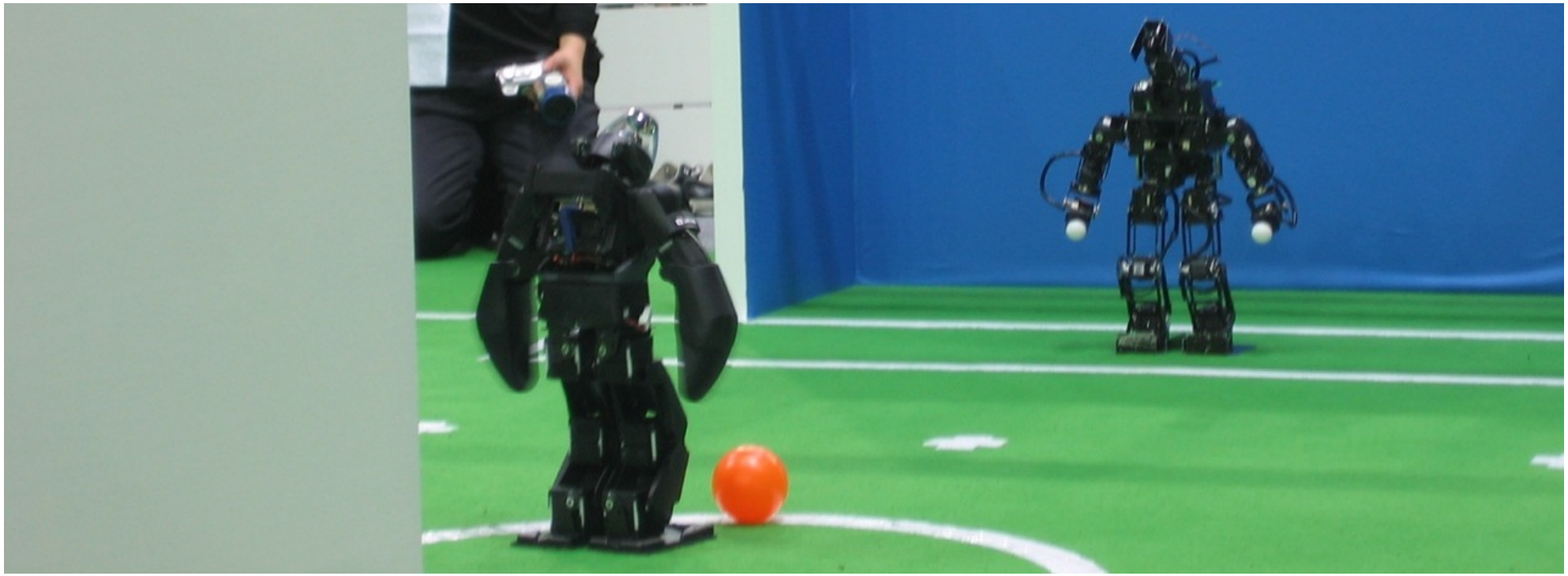
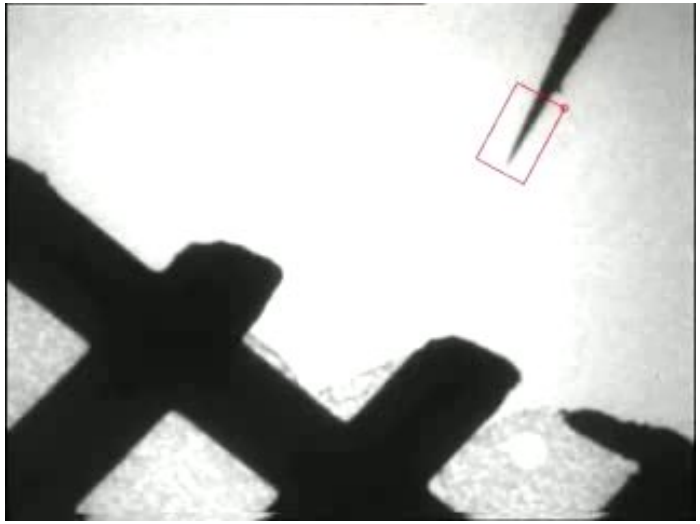
Embassy Suites San Francisco Airport, Room 1

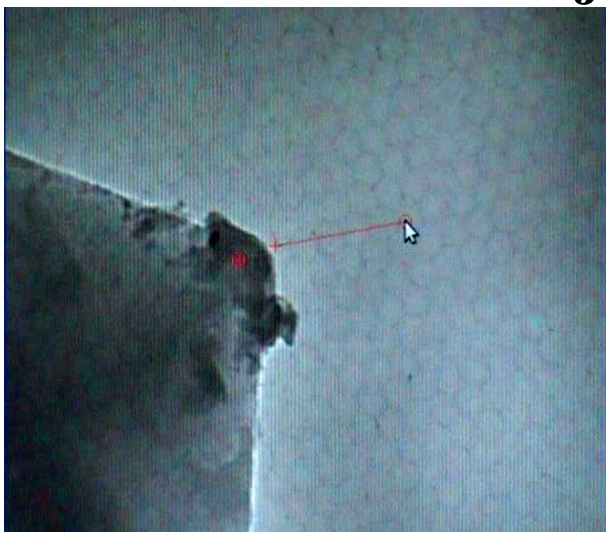


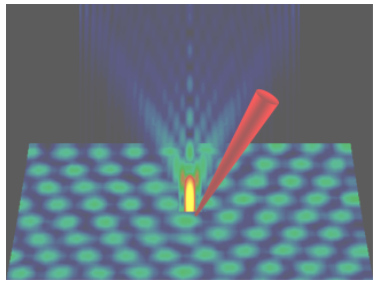
http://www.flickr.com/photos/schoschie/171544759/

Background

EPSRC Nanorobotics Project







EPSRC

http://vision.eng.shu.ac.uk/mmvlwiki/index.php/Nanorobotics

http://nano.group.shef.ac.uk/

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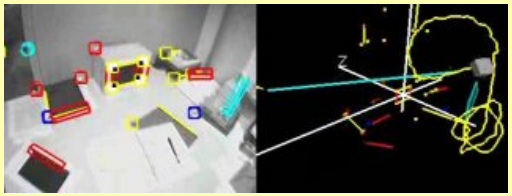
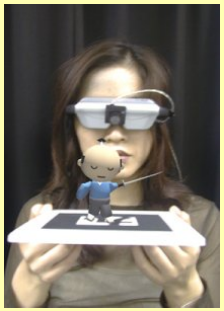
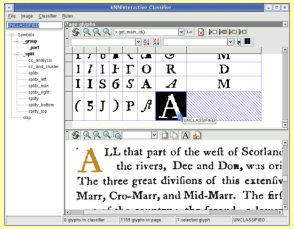
Applications of Computer Vision



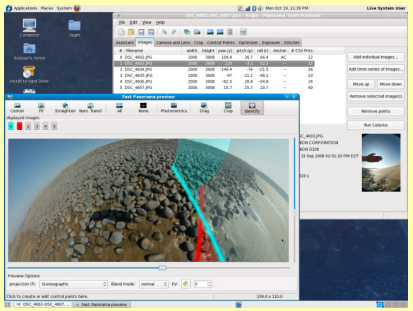
Visual Navigation



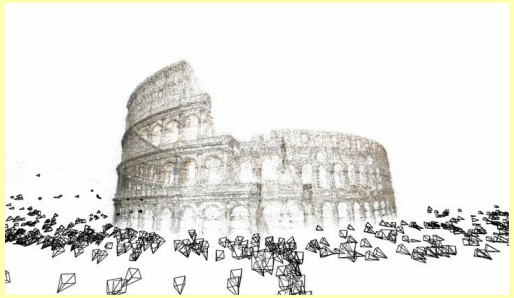
Augmented Reality



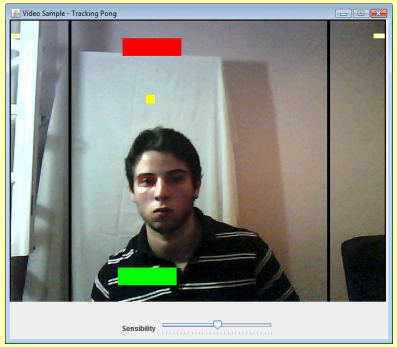
Optical Character Recognition



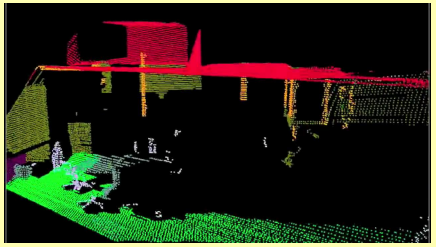
Panorama Stitching



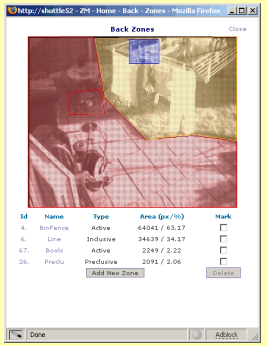
3D Reconstruction



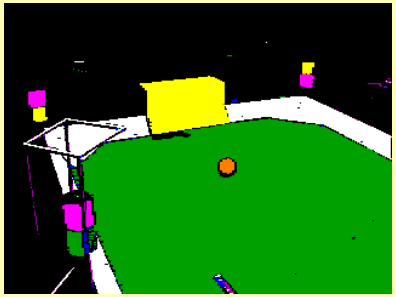
Games



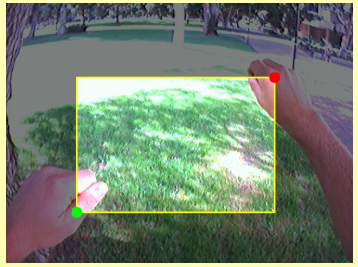
3D Object Recognition



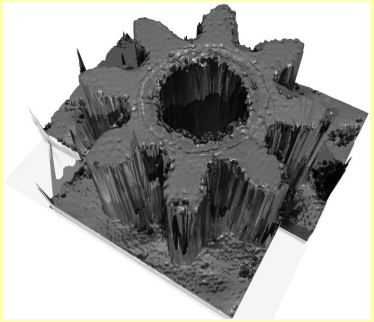
Surveillance



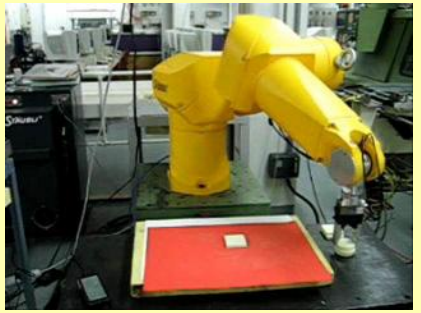
Segmentation



Human Computer Interfaces



Inspection



Automation

The Array Challenge

Computer Vision means Array Operations

C/C++

```c
#include <stdlib.h>
#define SIZE 10000000
int main(void)
{
  int i, *arr = (int *)
    malloc( SIZE *
            sizeof(int) );
  for ( i = 0; i < SIZE; i++ )
    arr[ i ] = i;
  free( arr );
  return 0;
}
```

gcc 4.2.4 0.06s

Ruby

```ruby
SIZE = 10000000
arr = ( 0 ... SIZE ).
  collect { |i| i }
```

ruby 1.8.6 76.3s

ruby 1.9.1 1.8s

Intel® Core™2 CPU T5600 @ 1.83GHz

Linux 2.6.24-24-generic SMP i686 GNU/Linux

Maybe we shouldn't use Ruby here?

http://www.imdb.com/title/tt0343818/

Expressiveness (multi-dimensional '+')

C++ and Boost::MultiArray

```
#include <boost/multi_array.hpp> // 3726 lines of code
#include <iostream>
using namespace boost;
template< typename T >
T &multi_plus( T &a, const T &b, const T &c )
{
  a = b + c;
  return a;
}
template< template< typename, size_t, typename > class Arr,
          typename Alloc, typename T, size_t N >
detail::multi_array::sub_array< T, N > multi_plus
( detail::multi_array::sub_array< T, N > a,
  const Arr< T, N, Alloc > &b, const Arr< T, N, Alloc > &c )
{
  typename Arr< T, N, Alloc >::const_iterator j = b.begin();
  typename Arr< T, N, Alloc >::const_iterator k = c.begin();
  for ( typename detail::multi_array::sub_array< T, N >::
          iterator i = a.begin(); i != a.end(); i++, j++, k++ )
    multi_plus( *i, *j, *k );
  return a;
}
template< template< typename, size_t, typename > class Arr,
          typename Alloc, typename T, size_t N >
Arr< T, N, Alloc > &multi_plus
( Arr< T, N, Alloc > &a,
  const Arr< T, N, Alloc > &b, const Arr< T, N, Alloc > &c )
{
  typename Arr< T, N, Alloc >::const_iterator j = b.begin();
  typename Arr< T, N, Alloc >::const_iterator k = c.begin();
  for ( typename Arr< T, N, Alloc >::
          iterator i = a.begin(); i != a.end(); i++, j++, k++ )
    multi_plus( *i, *j, *k );
  return a;
}
```

```
template < template< typename, size_t, typename > class Arr,
           typename Alloc, typename T, size_t N >
multi_array< T, N > operator+
( const Arr< T, N, Alloc > &a,
  const Arr< T, N, Alloc > &b )
{
  array< size_t, N > shape;
  std::copy( a.shape(), a.shape() + N, shape.begin() );
  multi_array< T, N > retVal( shape );
  multi_plus( retVal, a, b );
  return retVal;
};
int main(void)
{
  multi_array< int, 2 > a( extents[ 2 ][ 2 ] );
  a[0][0] = 1; a[0][1] = 2; a[1][0] = 3; a[1][1] = 4;
  multi_array< int, 2 > b( extents[ 2 ][ 2 ] );
  b[0][0] = 5; b[0][1] = 4; b[1][0] = 3; b[1][1] = 2;
  multi_array< int, 2 > r( a + b );
  std::cout << "[ [ " << r[0][0] << ", " << r[0][1]
            << " ], [ " << r[1][0] << ", " << r[1][1]
            << " ] ]" << std::endl;
  // [ [ 6, 6 ], [ 6, 6 ] ]
  return 0;
}
```

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Expressiveness (multi-dimensional '+')

Ruby and Standard Library

```ruby
class Array
  def +( other )
    zip( other ).collect { |x,y| x + y }
  end
end
a = [ [ 1, 2 ], [ 3, 4 ] ]
b = [ [ 5, 4 ], [ 3, 2 ] ]
puts ( a + b ).inspect
# [ [ 6, 6 ], [ 6, 6 ] ]
```

straightforward!

Implementation

Uniform Arrays

[ ,  ,  ,  ,  ,  ,  , ...]

Also see: NArray

Implementation

Malloc Objects

```
m = Malloc.new 10

m.write '0123456789'

# "0123456789"

m.read 5

# "01234"

( m + 2 ).read 5

# "23456"
```

Implementation

Using 'Array#pack' and 'String#unpack'

```ruby
class INT
  def initialize( v = 0 )
    @malloc = Malloc.new 4
    set v
  end
  def inspect
    "#{ self.class.inspect }(#{ get })"
  end
  def set( v = 0 )
    @malloc.write [ v ].pack( 'i' )
    v
  end
  def get
    @malloc.read( 4 ).unpack( 'i' )[ 0 ]
  end
end
```

```ruby
i = INT.new 3
# INT(3)
i.set 5
# 5
i
# INT(5)
i.get
# 5
```

Implementation

Type System: Generic Native Scalar

```
class INT_
  class << self
    attr_accessor :bits
    attr_accessor :signed
  end
  # ...
end
SIGNED   = true
UNSIGNED = false
def INT( bits, signed )
  retval = Class.new INT_
  retval.bits = bits
  retval.signed = signed
  retval
end
```

```
USINT = INT 16, UNSIGNED
# USINT
u = USINT.new 3
# USINT(3)
v = USINT.new u.malloc
# USINT(3)
```

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Implementation

Type System: Native Arrays

```
class Sequence_
  class << self
    attr_accessor :elem, :num,
                  :stride
  end
  # ...
  def sel( i )
    elem.new @malloc + i *
             elem.bytes * stride
  end
  def []( i )
    sel( i ).get
  end
  def []=( i, v )
    sel( i ).set v
  end
end
```

```
SINT = INT 16, SIGNED
# SINT
s = Sequence( SINT, 8 ).new.fill!
# Sequence(SINT,8):
# [ 0, 0, 0, 0, 0, 0, 0, 0 ]
s[ 3 ] = 5
# 5
s
# Sequence(SINT,8):
# [ 0, 0, 0, 5, 0, 0, 0, 0 ]
s[ 3 ]
# 5
s.sel 3
# SINT(5)
```

Implementation

Type System: Recursive Arrays

```
M = Sequence( Sequence( INT( 32, SIGNED ), 3 ), 2 )
# MultiArray.int(3,2)
m = M.new.fill! 1
# MultiArray.int(3,2):
# [ [ 1, 1, 1 ],
#   [ 1, 1, 1 ] ]
m[ 1 ]
# Sequence.int(3):
# [ 1, 1, 1 ]
m[ 2, 1 ]
# 1
m[ 1 ][ 2 ] = 0
# 0
m[ 1 .. 2, 0 .. 1 ]
# MultiArray.int(2,2):
# [ [ 1, 1 ],
#   [ 1, 0 ] ]
```

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Array Operations

Implementation

Array Operations: Scalar Operations

```
module RubyScalar
  def op( *args, &action )
    instance_exec *args, &action
    self
  end
  def -@
    self.class.new.op( get ) { |x| set -x }
  end
  # ...
end
class INT_
  include RubyScalar
end
```

```
i = SINT.new 3
# SINT(3)
-i
# SINT(-3)
```

Implementation

Array Operations: Element-Wise Array Operations

```
module RubySequence
  def op( *args, &action )
    for i in 0 ... num
      subargs = args.collect do |v|
        v.is_a?( Sequence_ ) ? v[ i ] : v
      end
      sel( i ).op *subargs, &action
    end
    self
  end
  def -@
    self.class.new.op( get ) { |x| set -x }
  end
end
class Sequence_
  include RubySequence
end
```

```
S = Sequence( INT, 3 )
# Sequence.int(3)
s = S.new.indgen!
# Sequence.int(3):
# [ 0, 1, 2 ]
-s
# Sequence.int(3):
# [ 0, -1, -2 ]
```

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How to speed-up things?

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Implementation

Reflection in Ruby: Example

```ruby
class Const
  attr_accessor :inspect
  alias_method :to_s, :inspect
  def initialize( s )
    @inspect = s.to_s
  end
  def method_missing( name, *args )
    str = "#{ self }.#{ name }"
    unless args.empty?
      str += "( #{args.join ', '} )"
    end
    Const.new str
  end
  def coerce( y )
    return Const.new( y ), self
  end
end
```

```ruby
a = Const.new 'a'
# a
b = Const.new 'b'
# b
-a
# a.-@
a + b
# a.+( b )
a[ 2 ]
# a[]( 2 )
2 * a
# 2.*( a )
2 * a + b
# 2.*( a ).+( b )
2 * ( a + b )
# 2.*( a.+( b ) )
```

Implementation

Reflection in Ruby: Limitations

```
a or b
# a

a < b ? a : b
# a

b = a
# a

if a > b
  a -= b
end
# a.-( b )

begin
  a += 1
end until a > b
a
# a.+( 1 )
```

```
b and a
# a

a > b ? a : b
# a

x = a
# a

a - b
#
#
# a.-( b )

b = a + 1
#
#
#
# a.+( 1 )
```

Implementation

JIT-Compilation: Scalar Operation I/II

```
module JITScalar
  def op( *args, &action )
    if ( [ self ] + args ).all? { |arg| arg.jit_support? }
      JITFunction.jit( self, *args ) do |f,_self,*_args|
        _self.op *_args, &action
      end
      self
    else
      super *args, &action
    end
  end
end
class INT_
  include JITScalar
end
```

'JITFunction.jit': cache, compile, and execute

Implementation

JIT-Compilation: Scalar Operation II/II

```
i = INT.new 3
# INT(3)
i.class.new.op( i.get ) do |x|
  puts "self = #{self}"
  puts "x    = #{x}"
  puts
  set -x
end
# self = INT(*i1)
# x    = i2

# INT(-3)
```

```
function -@( i1:  ptr,
             i2:  int ):  void
  i3 = -i2
  *i1 = i3
```

machine code generated by libJIT/ DotGNU

http://freshmeat.net/projects/libjit/

Also see: ruby-libjit

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Implementation

JIT-Compilation: Array Operation I/V

```
module JITSequence
  def op( *args, &action )
    if ( [ self ] + args ).all? { |arg| arg.jit_support? }
      JITFunction.jit( self, *args ) do |f,_self,*_args|
        _self.op *_args, &action
      end
      self
    elsif is_jit?
      f = malloc.f
      r = JITTerm.value f, JITType::PTR, malloc
      s = stride * elem.bytes
      rend = r + s * num
```

Implementation

JIT-Compilation: Array Operation II/V

```
extract, increment = [], []
args.each do |arg|
  if arg.is_a? Sequence_
    ptr = JITTerm.value f, JITType::PTR, arg.malloc
    astride = arg.stride * arg.elem.bytes
    extract.push proc { arg.elem.new( ptr ).get }
    increment.push proc { ptr.set ptr + astride }
  else
    extract.push proc { arg }
  end
end
```

Implementation

JIT-Compilation: Array Operation III/V

```
      f.until( proc { r == rend } ) do
        _subargs = extract.collect { |i| i.call }
        elem.new( r ).op *_subargs, &action
        increment.each { |i| i.call }
        r.set r + s
      end
    else
      super *args, &action
    end
  end
end
class Sequence_
  include JITSequence
end
```

Also cumbersome but much more generic!

Implementation

JIT-Compilation: Array Operation IV/V

```
s = Sequence( INT, 3 ).new.indgen!
# Sequence(INT,3):
# [ 0, 1, 2 ]
s.class.new.op( s.get ) do |x|
  puts "self = #{self}"
  puts "x    = #{x}"
  puts
  set -x
end
# self = INT(*i7)
# x    = i13

# Sequence(INT,3):
# [ 0, -1, -2 ]
```

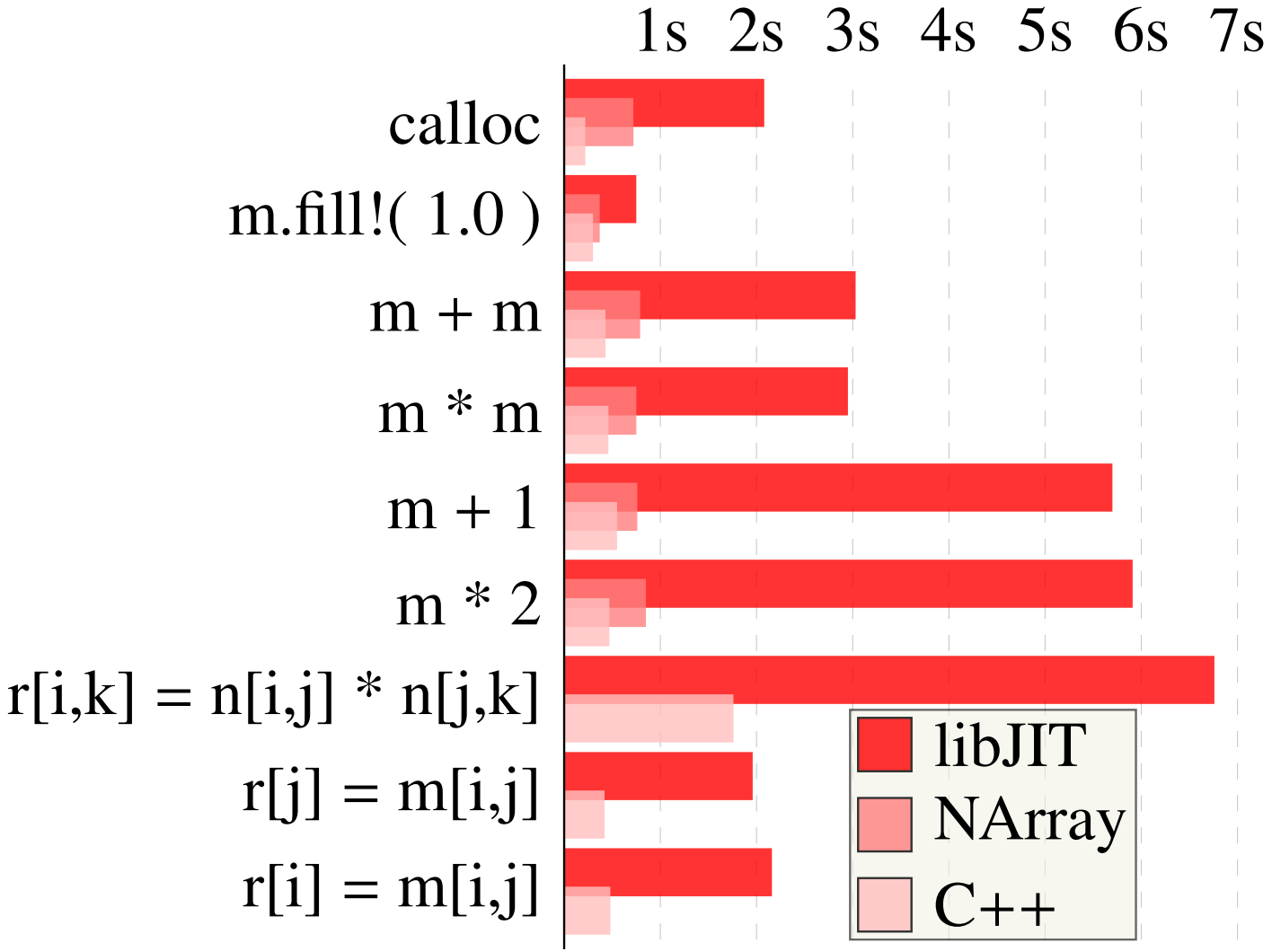
Implementation

JIT-Compilation: Array Operation V/V

```
function -@( i1:  int, i2:  int, i3:  ptr,
             i4:  int, i5:  int, i6:  ptr ):  void
  i7 = i3
  i8 = i2 * 4
  i9 = i8 * i1
  i10 = i7 + i9
  i11 = i6
  i12 = i5 * 4
L0:
  if i7 == i10 then goto L1
  i13 = *i11
    i14 = -i13
    *i7 = i14
  i11 = i11 + i12
  i7 = i7 + i8
  goto L0
L1:
```

Implementation

JIT Results



Intel® Core™2 CPU T5600 @ 1.83GHz

Linux 2.6.24-24-generic SMP i686 GNU/Linux

⇒ future work: prefill cache with GCC code (use RubyInline?)

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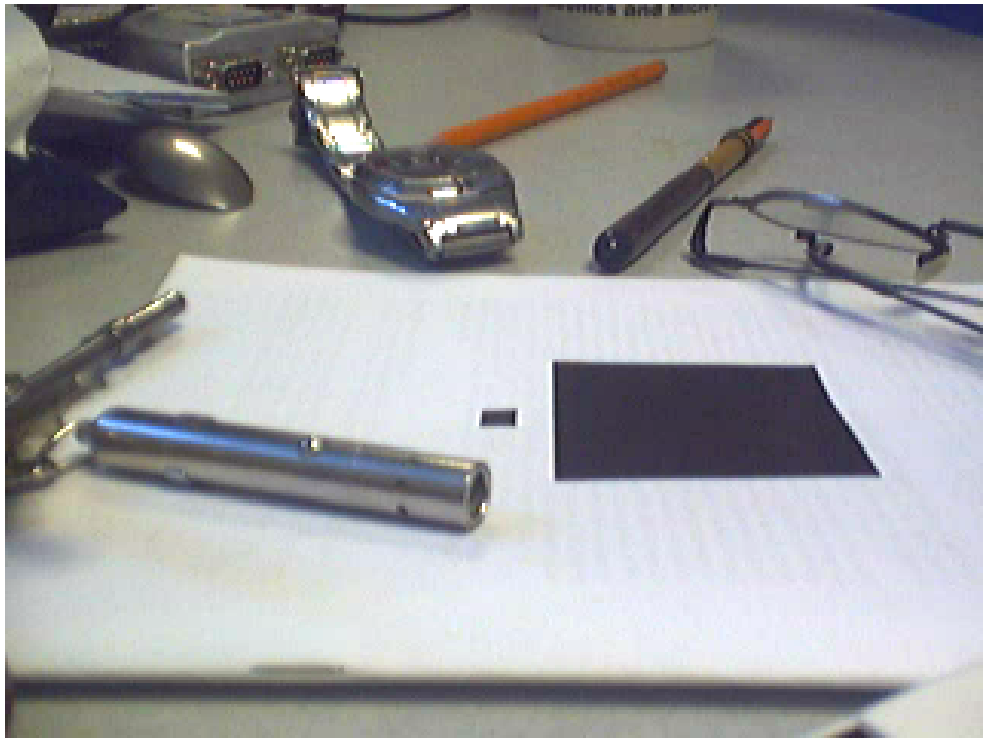
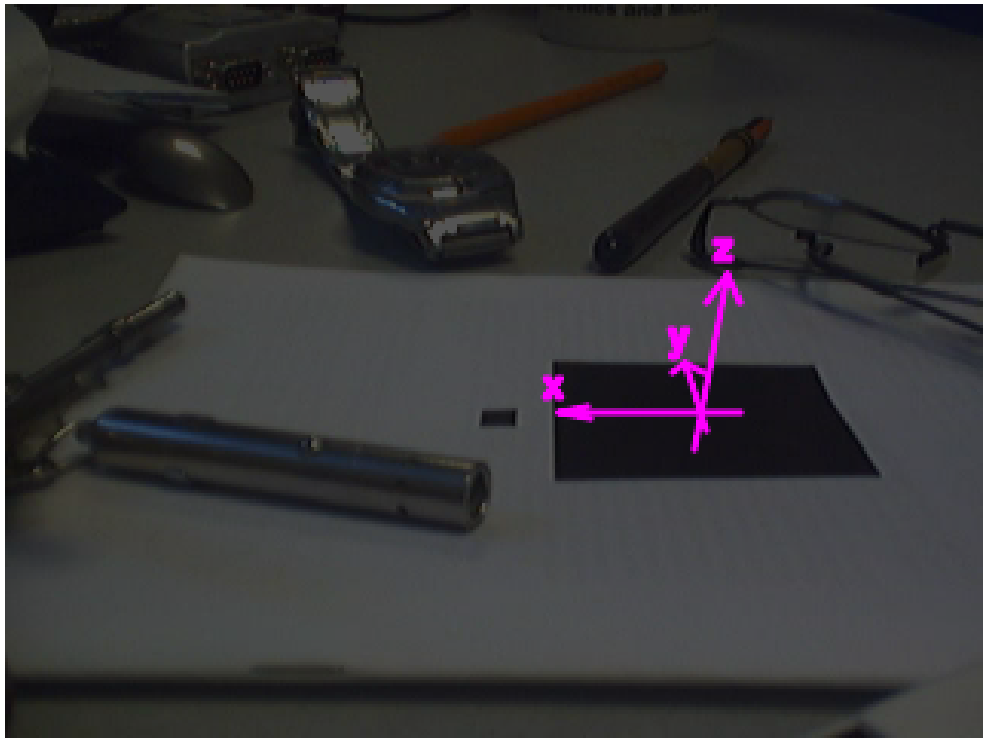
Augmented Reality Example

Problem: 3D recognition of planar object

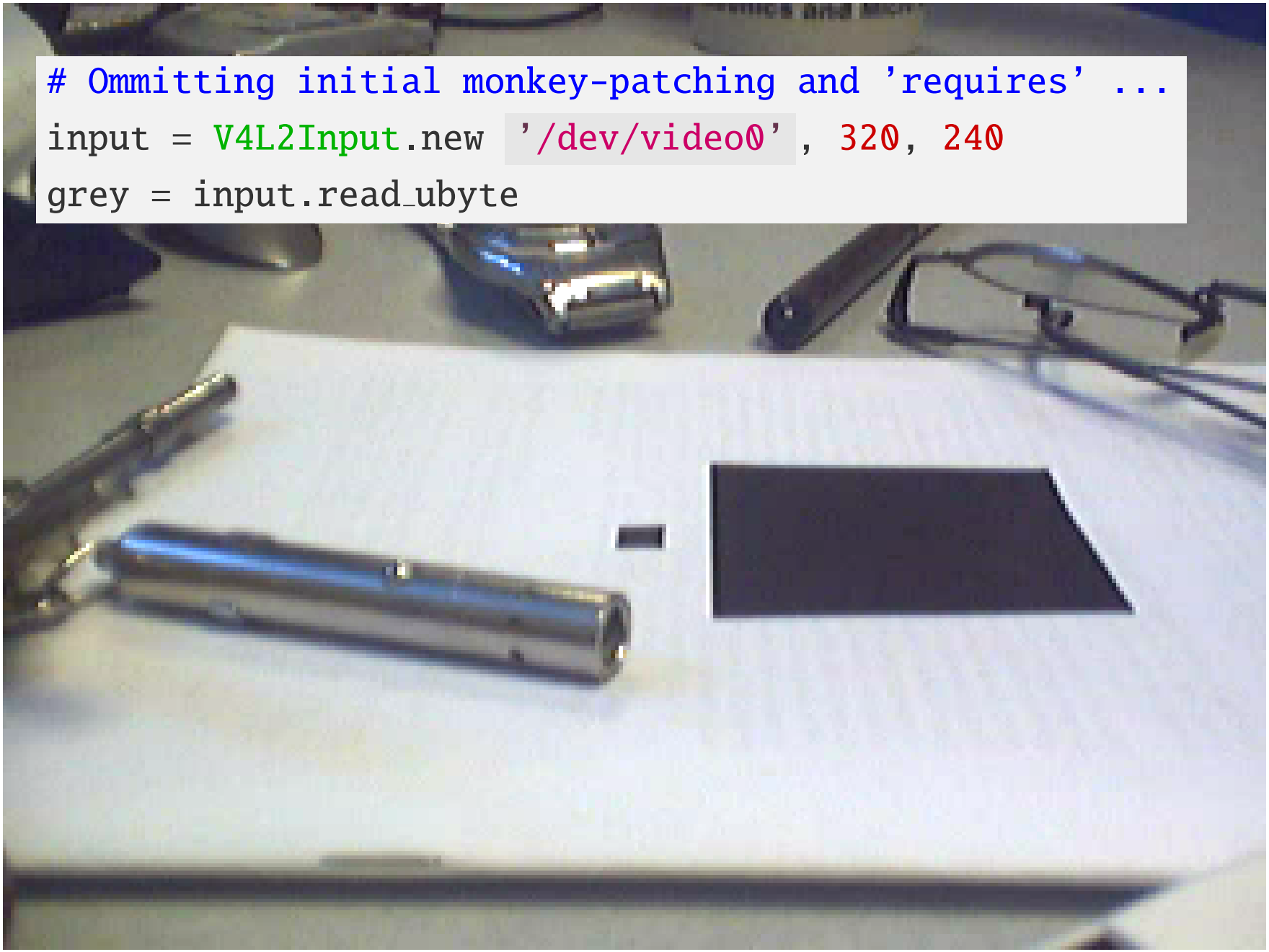
How to get from here . . . . . to here?





Augmented Reality Example

Capture Image



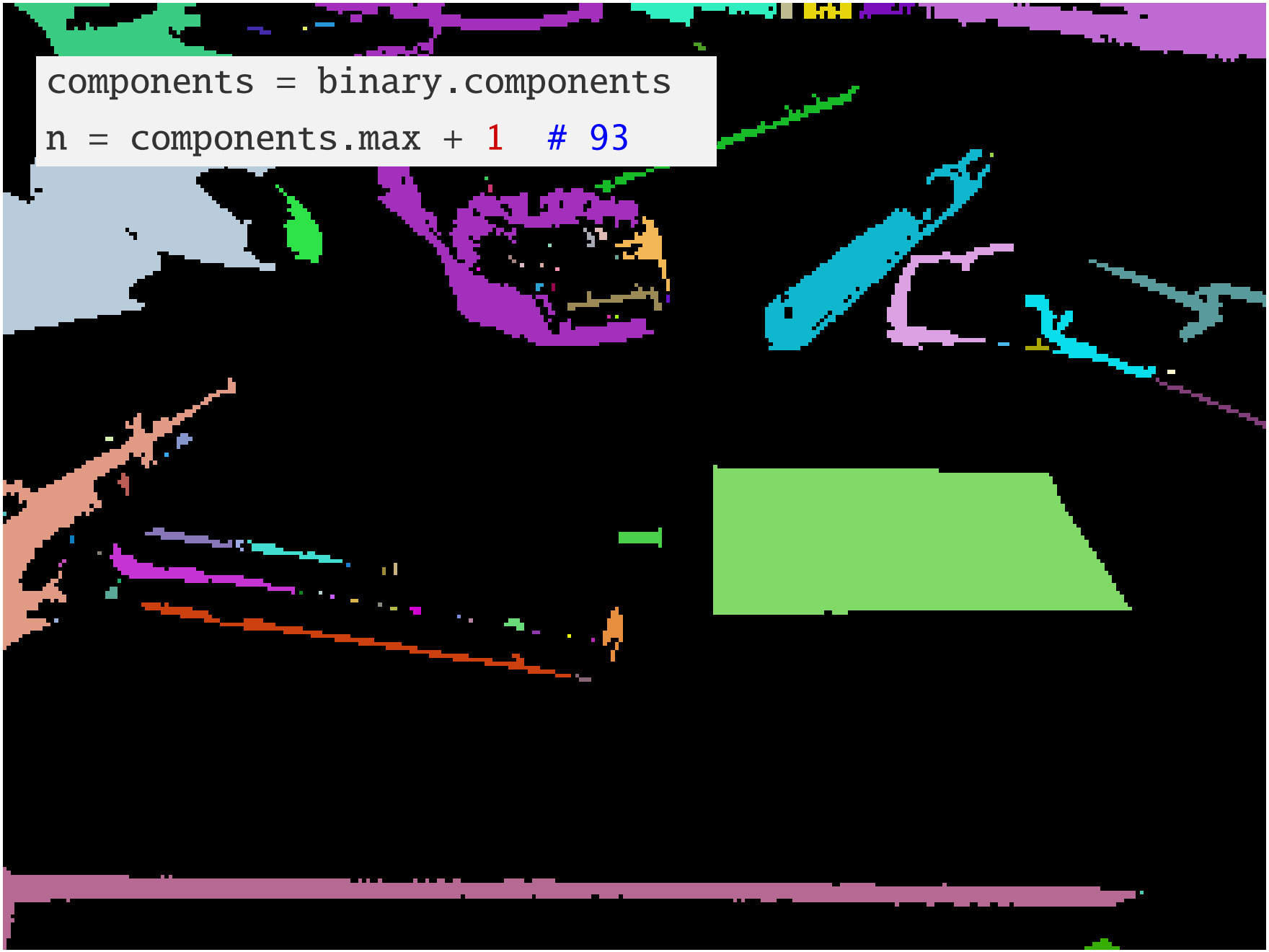

```
# Ommitting initial monkey-patching and 'requires' ...
input = V4L2Input.new '/dev/video0', 320, 240
grey = input.read_ubyte
```

Augmented Reality Example

Threshold Image

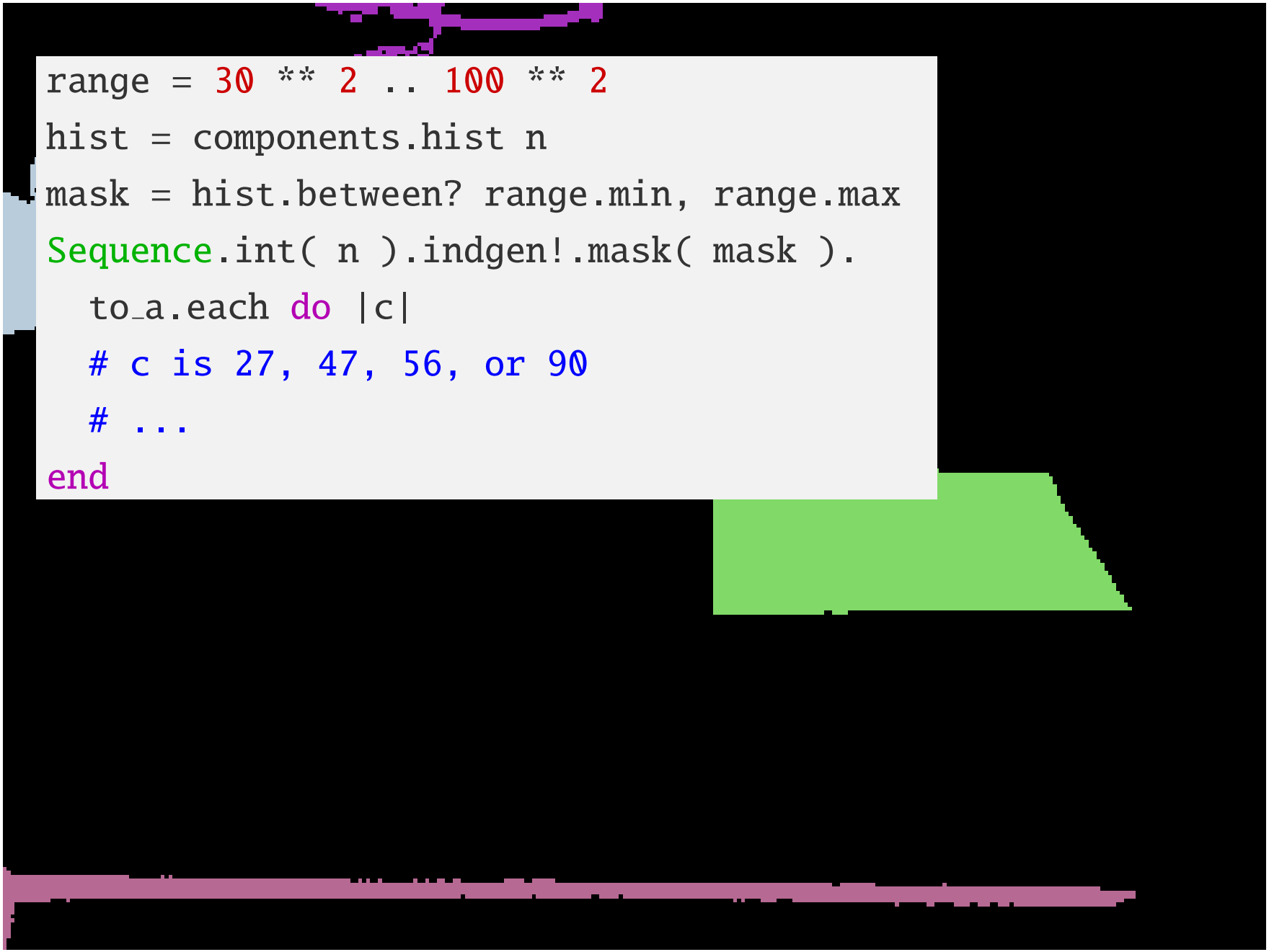
Augmented Reality Example

Connected Component Analysis



Augmented Reality Example

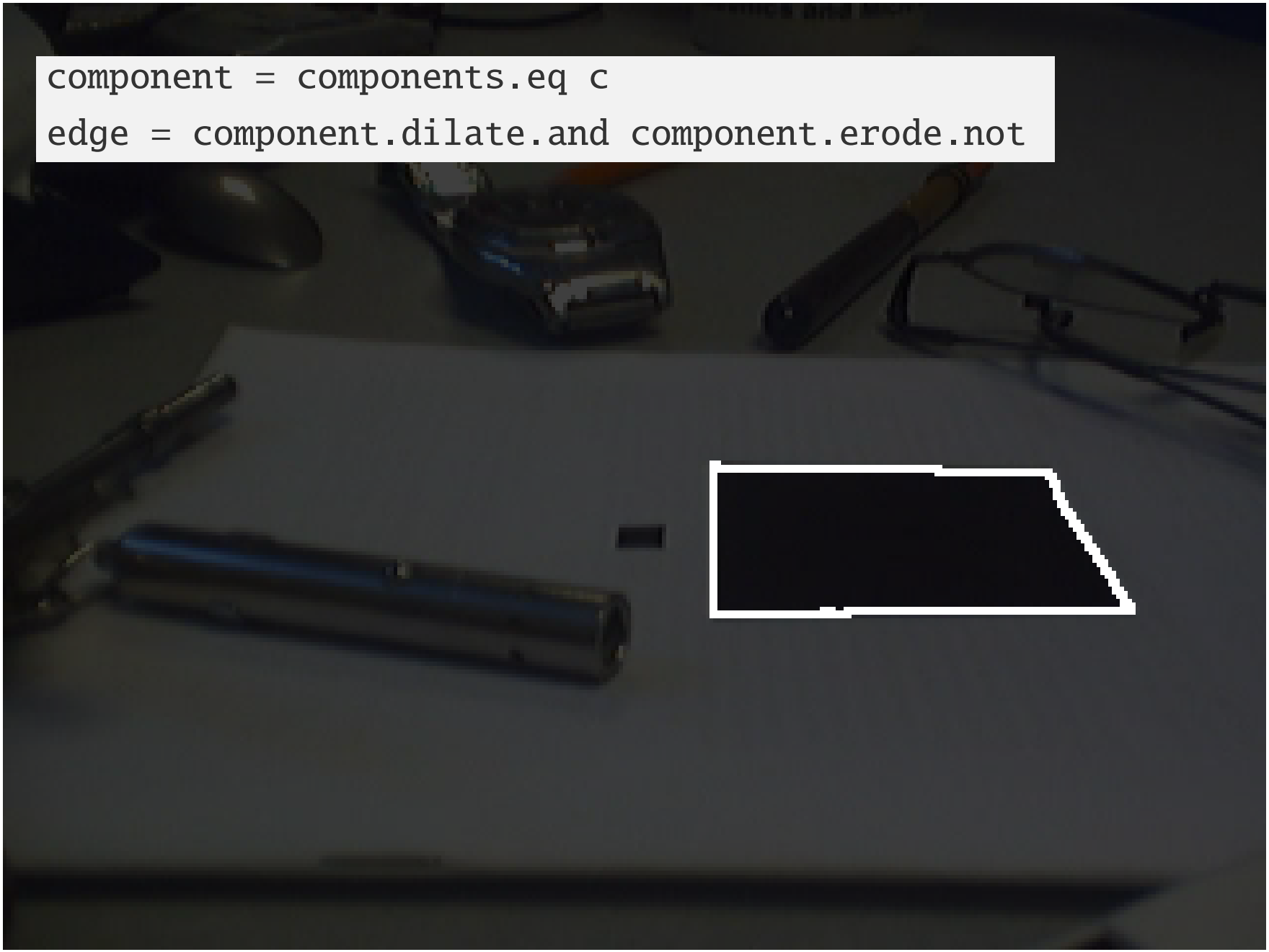
Impose Size Constraints



```
range = 30 ** 2 .. 100 ** 2
hist = components.hist n
mask = hist.between? range.min, range.max
Sequence.int( n ).indgen!.mask( mask ).
  to_a.each do |c|
  # c is 27, 47, 56, or 90
  # ...
end
```

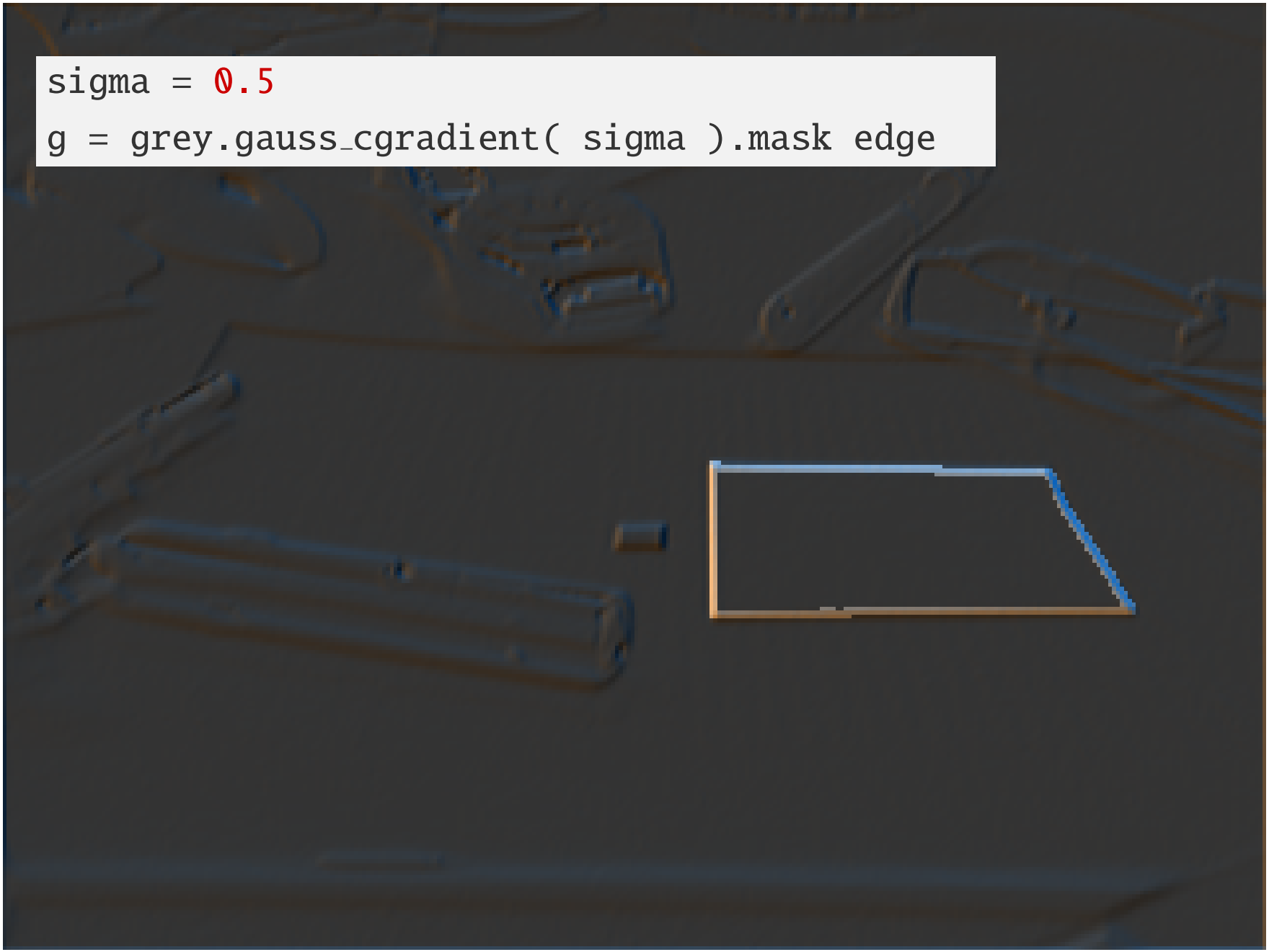
Augmented Reality Example

Extract Edge of Component



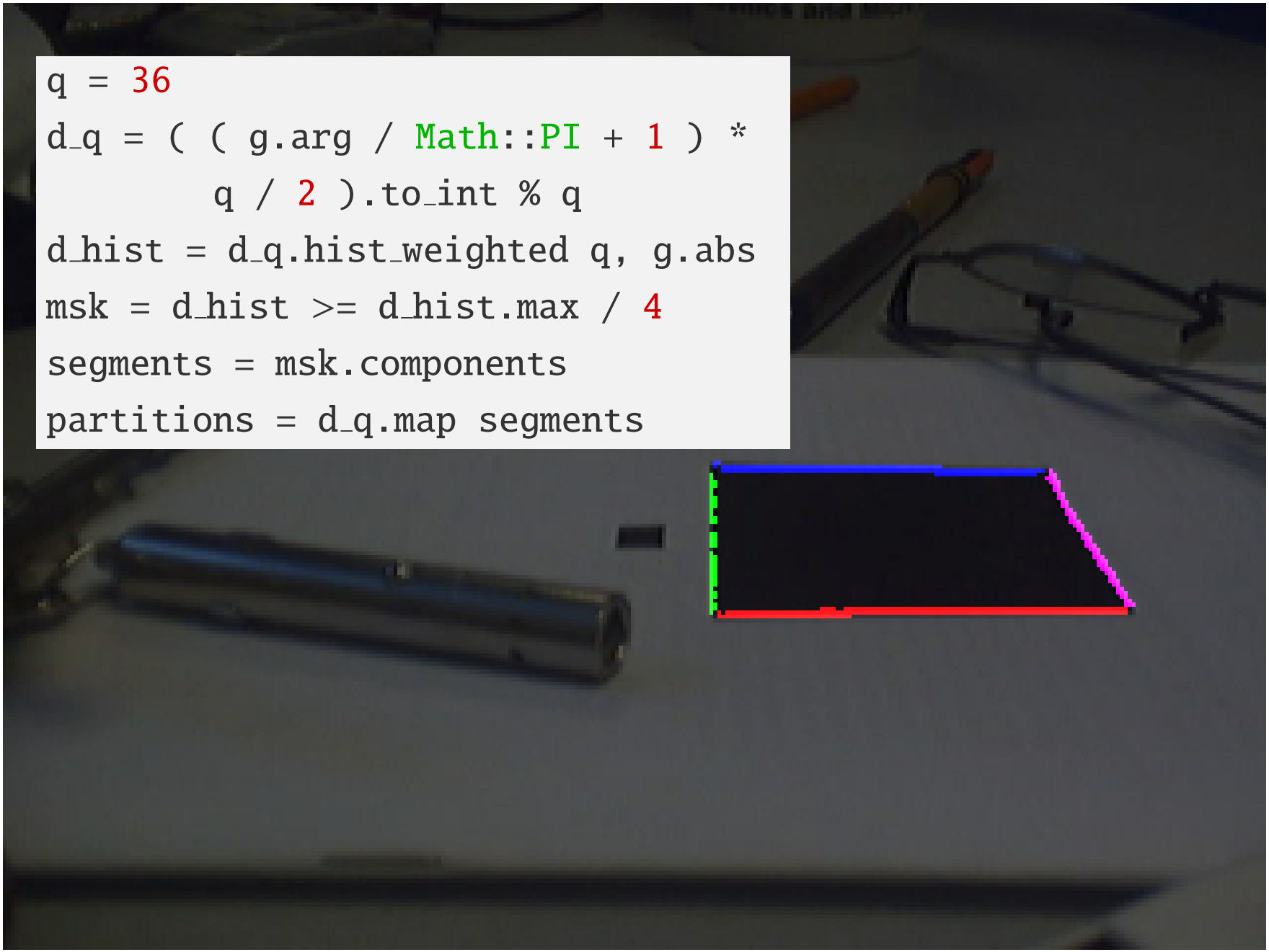
Augmented Reality Example

Compute Gradients



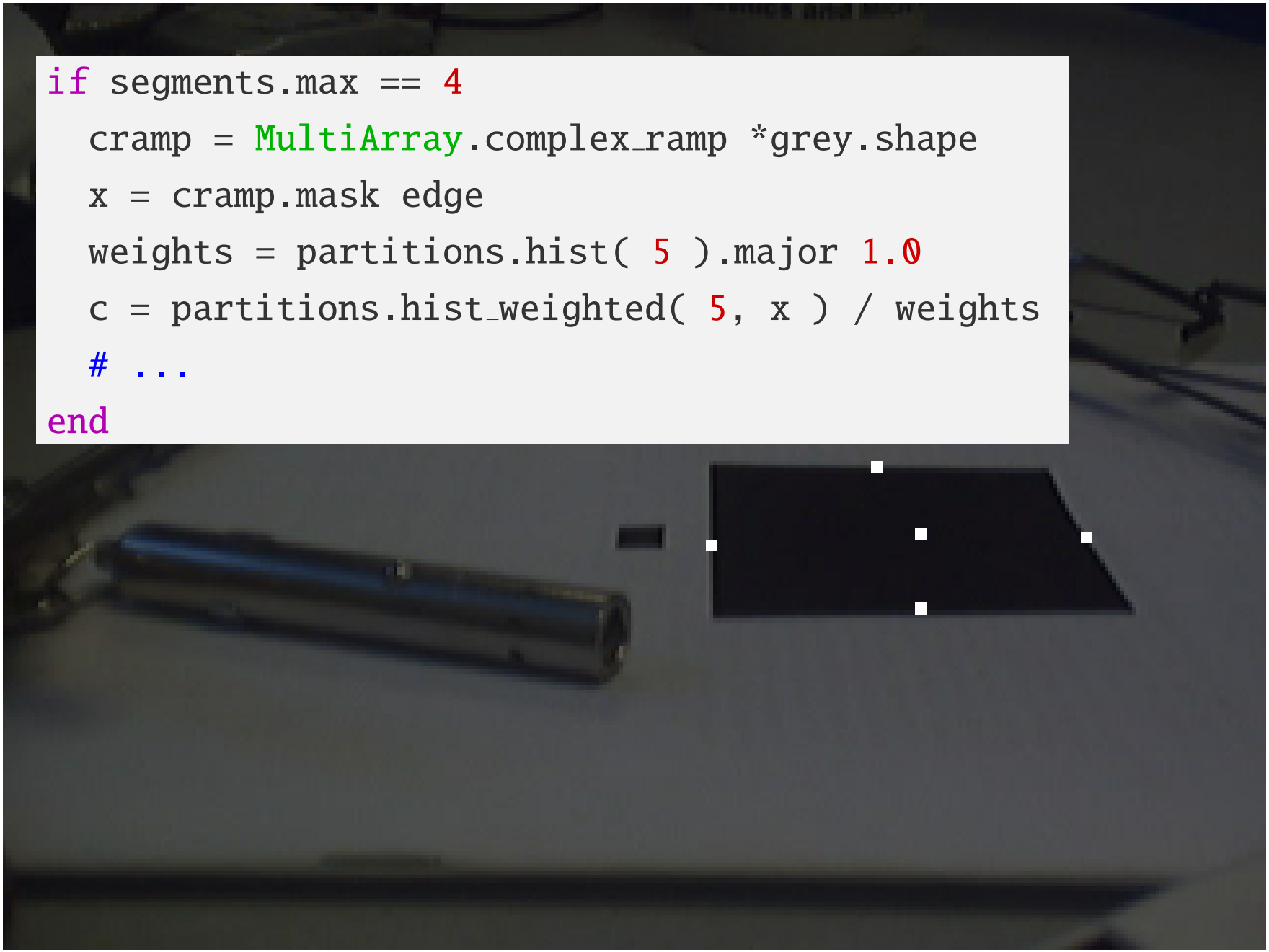
Augmented Reality Example

Group Dominant Orientations



Augmented Reality Example

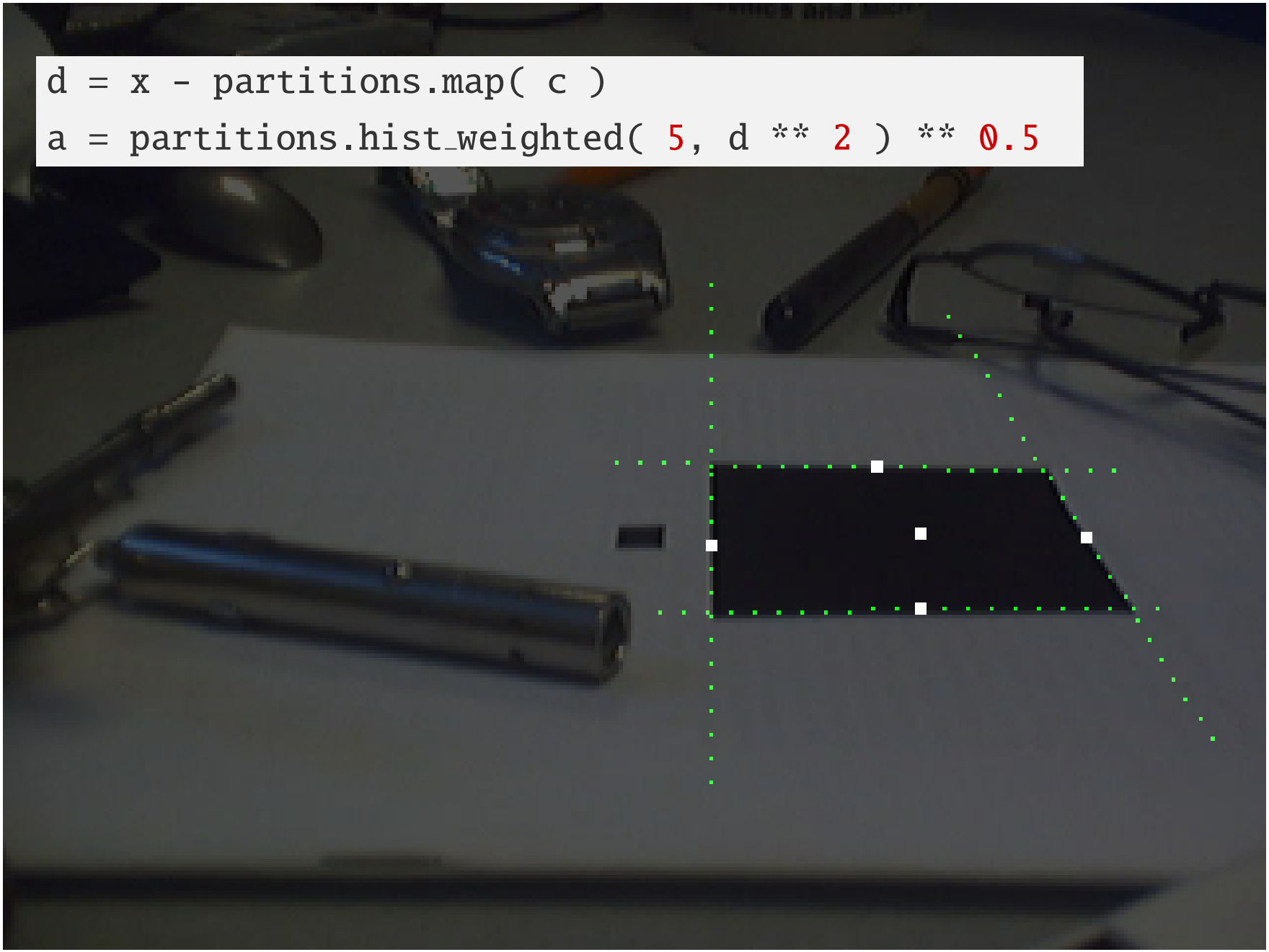
Centre of each Line



```
if segments.max == 4
  cramp = MultiArray.complex_ramp *grey.shape
  x = cramp.mask edge
  weights = partitions.hist( 5 ).major 1.0
  c = partitions.hist_weighted( 5, x ) / weights
  # ...
end
```

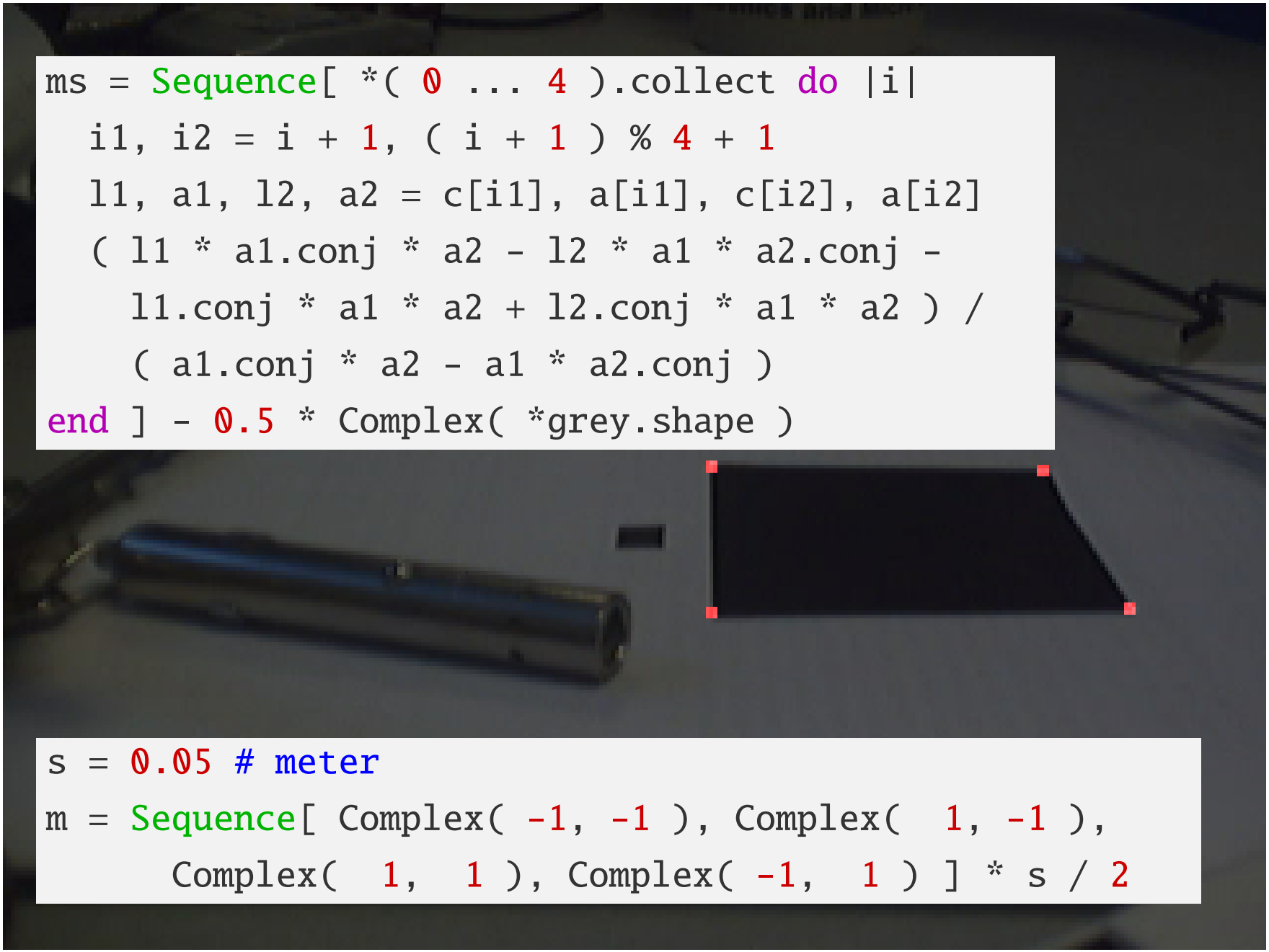
Augmented Reality Example

Angle of each Line



Augmented Reality Example

Intersections



Hornets Eye

Augmented Reality Example

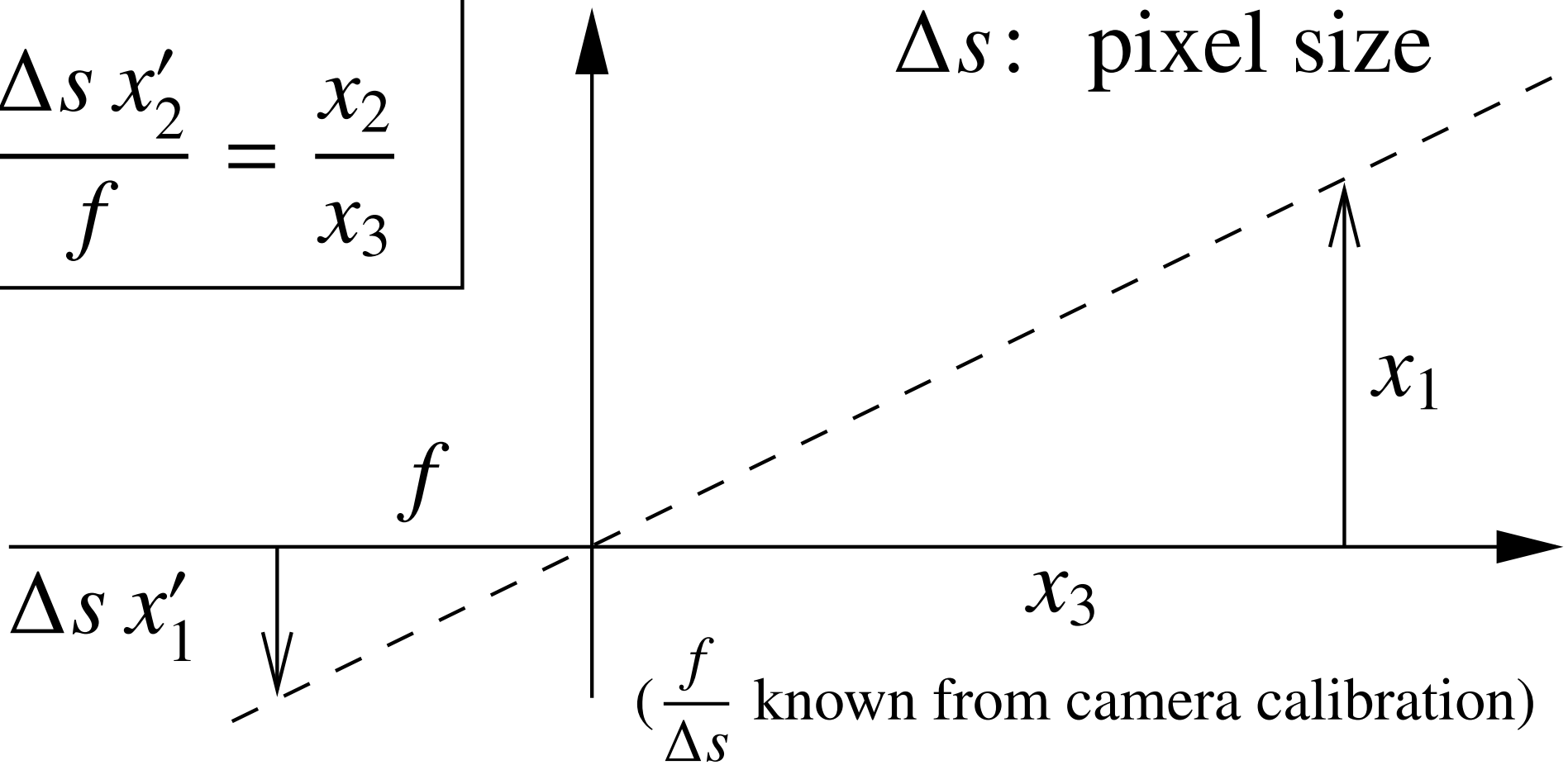
3D Pose: Pinhole Camera Model

$$\frac{\Delta s\, x'_1}{f} = \frac{x_1}{x_3}$$

$$\frac{\Delta s\, x'_2}{f} = \frac{x_2}{x_3}$$

f : focal length

Δs: pixel size



Hornets Eye

Augmented Reality Example

3D Pose: Homogeneous Coordinates

$$x_3\, x'_1 = \frac{f}{\Delta s}\, x_1$$

$$x_3\, x'_2 = \frac{f}{\Delta s}\, x_2$$

$$\lambda\, x'_1 = \frac{f}{\Delta s}\, x_1$$

$$\Leftrightarrow \exists \lambda \in \mathbb{R}/\{0\} : \quad \lambda\, x'_2 = \frac{f}{\Delta s}\, x_2$$

$$\lambda = x_3$$

$$\Leftrightarrow \exists \lambda \in \mathbb{R}/\{0\} : \quad \lambda \begin{pmatrix} x'_1 \\ x'_2 \\ 1 \end{pmatrix} = \underbrace{\begin{pmatrix} f/\Delta s & 0 & 0 \\ 0 & f/\Delta s & 0 \\ 0 & 0 & 1 \end{pmatrix}}_{\text{intrinsic camera parameters}} \begin{pmatrix} x_1 \\ x_2 \\ x_3 \end{pmatrix}$$

Hornets Eye

Augmented Reality Example

3D Pose: (Additional) Affine Transform

$$\exists \lambda \in \mathbb{R}/\{0\} : \lambda \begin{pmatrix} x'_1 \\ x'_2 \\ 1 \end{pmatrix} = \begin{pmatrix} f/\Delta s & 0 & 0 \\ 0 & f/\Delta s & 0 \\ 0 & 0 & 1 \end{pmatrix} \left(\begin{pmatrix} r_{11} & r_{12} & r_{13} \\ r_{21} & r_{22} & r_{23} \\ r_{31} & r_{32} & r_{33} \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \\ x_3 \end{pmatrix} + \begin{pmatrix} t_1 \\ t_2 \\ t_3 \end{pmatrix} \right)$$

$$\Leftrightarrow \exists \lambda \in \mathbb{R}/\{0\} : \lambda \begin{pmatrix} x'_1 \\ x'_2 \\ 1 \end{pmatrix} = \begin{pmatrix} f/\Delta s & 0 & 0 \\ 0 & f/\Delta s & 0 \\ 0 & 0 & 1 \end{pmatrix} \underbrace{\begin{pmatrix} r_{11} & r_{12} & r_{13} & t_1 \\ r_{21} & r_{22} & r_{23} & t_2 \\ r_{31} & r_{32} & r_{33} & t_3 \end{pmatrix}}_{\text{extrinsic camera parameters}} \begin{pmatrix} x_1 \\ x_2 \\ x_3 \\ 1 \end{pmatrix}$$

$$\begin{pmatrix} x'_1 \\ x'_2 \end{pmatrix} \text{ is } \begin{pmatrix} m'_{11} \\ m'_{12} \end{pmatrix}, \begin{pmatrix} m'_{21} \\ m'_{22} \end{pmatrix}, \ldots, \begin{pmatrix} m'_{41} \\ m'_{42} \end{pmatrix} \text{ and } \begin{pmatrix} x_1 \\ x_2 \\ x_3 \end{pmatrix} \text{ is } \begin{pmatrix} m_{11} \\ m_{12} \\ 0 \end{pmatrix}, \begin{pmatrix} m_{21} \\ m_{22} \\ 0 \end{pmatrix}, \ldots, \begin{pmatrix} m_{41} \\ m_{42} \\ 0 \end{pmatrix}$$

Hornets Eye

Augmented Reality Example

3D Pose: Planar Homography I/II

Problem: Minimize ϵ_{ij}

$$\exists \lambda_i \in \mathbb{R}/\{0\} : \lambda_i \left(\begin{pmatrix} m'_{i1} \\ m'_{i2} \\ 1 \end{pmatrix} + \begin{pmatrix} \epsilon_{i1} \\ \epsilon_{i2} \\ 0 \end{pmatrix} \right) = \begin{pmatrix} f/\Delta s & 0 & 0 \\ 0 & f/\Delta s & 0 \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} r_{11} & r_{12} & r_{13} & t_1 \\ r_{21} & r_{22} & r_{23} & t_2 \\ r_{31} & r_{32} & r_{33} & t_3 \end{pmatrix} \begin{pmatrix} m_{i1} \\ m_{i2} \\ 0 \\ 1 \end{pmatrix}$$

$$\Leftrightarrow \exists \lambda_i \in \mathbb{R}/\{0\} : \lambda_i \left(\begin{pmatrix} m'_{i1} \\ m'_{i2} \\ 1 \end{pmatrix} + \begin{pmatrix} \epsilon_{i1} \\ \epsilon_{i2} \\ 0 \end{pmatrix} \right) = \underbrace{\begin{pmatrix} f/\Delta s & 0 & 0 \\ 0 & f/\Delta s & 0 \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} r_{11} & r_{12} & t_1 \\ r_{21} & r_{22} & t_2 \\ r_{31} & r_{32} & t_3 \end{pmatrix}}_{=:\mathcal{H}} \begin{pmatrix} m_{i1} \\ m_{i2} \\ 1 \end{pmatrix}$$

$$\Leftrightarrow \exists \lambda_i \in \mathbb{R}/\{0\} : \lambda_i \left(\begin{pmatrix} m'_{i1} \\ m'_{i2} \\ 1 \end{pmatrix} + \begin{pmatrix} \epsilon_{i1} \\ \epsilon_{i2} \\ 0 \end{pmatrix} \right) = \begin{pmatrix} h_{11} & h_{12} & h_{13} \\ h_{21} & h_{22} & h_{33} \\ h_{31} & h_{32} & h_{33} \end{pmatrix} \begin{pmatrix} m_{i1} \\ m_{i2} \\ 1 \end{pmatrix}, i \in \{1, 2, \ldots, 4\}$$

Hornets Eye

Augmented Reality Example

3D Pose: Planar Homography II/II

$$\Leftrightarrow \underbrace{(h_{31}\, m_{i1} + h_{32}\, m_{i2} + h_{33})}_{\lambda_i} \left(\begin{pmatrix} m'_{i1} \\ m'_{i2} \end{pmatrix} + \begin{pmatrix} \epsilon_{i1} \\ \epsilon_{i2} \end{pmatrix} \right) = \begin{pmatrix} h_{11} & h_{12} & h_{13} \\ h_{21} & h_{22} & h_{33} \end{pmatrix} \begin{pmatrix} m_{i1} \\ m_{i2} \\ 1 \end{pmatrix}$$

assuming $\lambda_1 \approx \lambda_2 \approx \ldots \approx \lambda_4$

this is approximately the same as

Problem: Minimize $\widetilde{\epsilon}_{ij}$

$$(h_{31}\, m_{i1} + h_{32}\, m_{i2} + h_{33}) \begin{pmatrix} m'_{i1} \\ m'_{i2} \end{pmatrix} + \begin{pmatrix} \widetilde{\epsilon}_{i1} \\ \widetilde{\epsilon}_{i2} \end{pmatrix} = \begin{pmatrix} h_{11} & h_{12} & h_{13} \\ h_{21} & h_{22} & h_{33} \end{pmatrix} \begin{pmatrix} m_{i1} \\ m_{i2} \\ 1 \end{pmatrix}$$

$$\Leftrightarrow \begin{pmatrix} \widetilde{\epsilon}_{i1} \\ \widetilde{\epsilon}_{i2} \end{pmatrix} = \begin{pmatrix} h_{11} & h_{12} & h_{13} \\ h_{21} & h_{22} & h_{33} \end{pmatrix} \begin{pmatrix} m_{i1} \\ m_{i2} \\ 1 \end{pmatrix} - (h_{31}\, m_{i1} + h_{32}\, m_{i2} + h_{33}) \begin{pmatrix} m'_{i1} \\ m'_{i2} \end{pmatrix}$$

Augmented Reality Example

3D Pose: Singular Value Decomposition

$$\underbrace{\begin{pmatrix} m_{11} & m_{12} & 1 & 0 & 0 & 0 & -m'_{11}m_{11} & -m'_{11}m_{12} & -m'_{11} \\ 0 & 0 & 0 & m_{11} & m_{12} & 1 & -m'_{12}m_{11} & -m'_{12}m_{12} & -m'_{12} \\ m_{21} & m_{22} & 1 & 0 & 0 & 0 & -m'_{21}m_{21} & -m'_{21}m_{22} & -m'_{21} \\ 0 & 0 & 0 & m_{21} & m_{22} & 1 & -m'_{22}m_{21} & -m'_{22}m_{22} & -m'_{22} \\ \vdots & \vdots & \vdots & \vdots & \vdots & \vdots & \vdots & \vdots & \vdots \\ m_{41} & m_{42} & 1 & 0 & 0 & 0 & -m'_{41}m_{41} & -m'_{41}m_{42} & -m'_{41} \\ 0 & 0 & 0 & m_{41} & m_{42} & 1 & -m'_{42}m_{41} & -m'_{42}m_{42} & -m'_{42} \end{pmatrix}}_{=:\mathcal{M}} \underbrace{\begin{pmatrix} h_{11} \\ h_{12} \\ \vdots \\ h_{33} \end{pmatrix}}_{=:\vec{h}} = \begin{pmatrix} \widetilde{\epsilon}_{11} \\ \widetilde{\epsilon}_{12} \\ \widetilde{\epsilon}_{21} \\ \widetilde{\epsilon}_{22} \\ \vdots \\ \widetilde{\epsilon}_{41} \\ \widetilde{\epsilon}_{42} \end{pmatrix}$$

$\|\vec{h}\| = \mu \neq 0$ to avoid trivial solution

I.e. find $\vec{h} \in \mathbb{R}^9 : \|\mathcal{M}\vec{h}\|$ minimal and $\|\vec{h}\| = \mu$

Solution: Perform SVD $\mathcal{M} = \mathcal{U}\Sigma\mathcal{V}^*$ and choose $\vec{h} = \mu\,\vec{v}_9$ where $\vec{v}_9$ is right-handed singular vector with the smallest singular value σ_9

Augmented Reality Example

3D Pose: 3D Homography

$$\mathcal{H} = \mu \begin{pmatrix} v_{91} & v_{92} & v_{93} \\ v_{94} & v_{95} & v_{96} \\ v_{97} & v_{98} & v_{99} \end{pmatrix} = \begin{pmatrix} f/\Delta s & 0 & 0 \\ 0 & f/\Delta s & 0 \\ 0 & 0 & 1 \end{pmatrix} \begin{pmatrix} r_{11} & r_{12} & t_1 \\ r_{21} & r_{22} & t_2 \\ r_{31} & r_{32} & t_3 \end{pmatrix}$$

$$\|\vec{r}_1\| = \|\vec{r}_2\| = 1$$

$$\vec{r}_3 = \vec{r}_1 \times \vec{r}_2$$

$$t_3 > 0$$

$$\vec{r}_3^{\top} \vec{t} \leq 0$$

$\Rightarrow$ Enough information to estimate 3D homography!

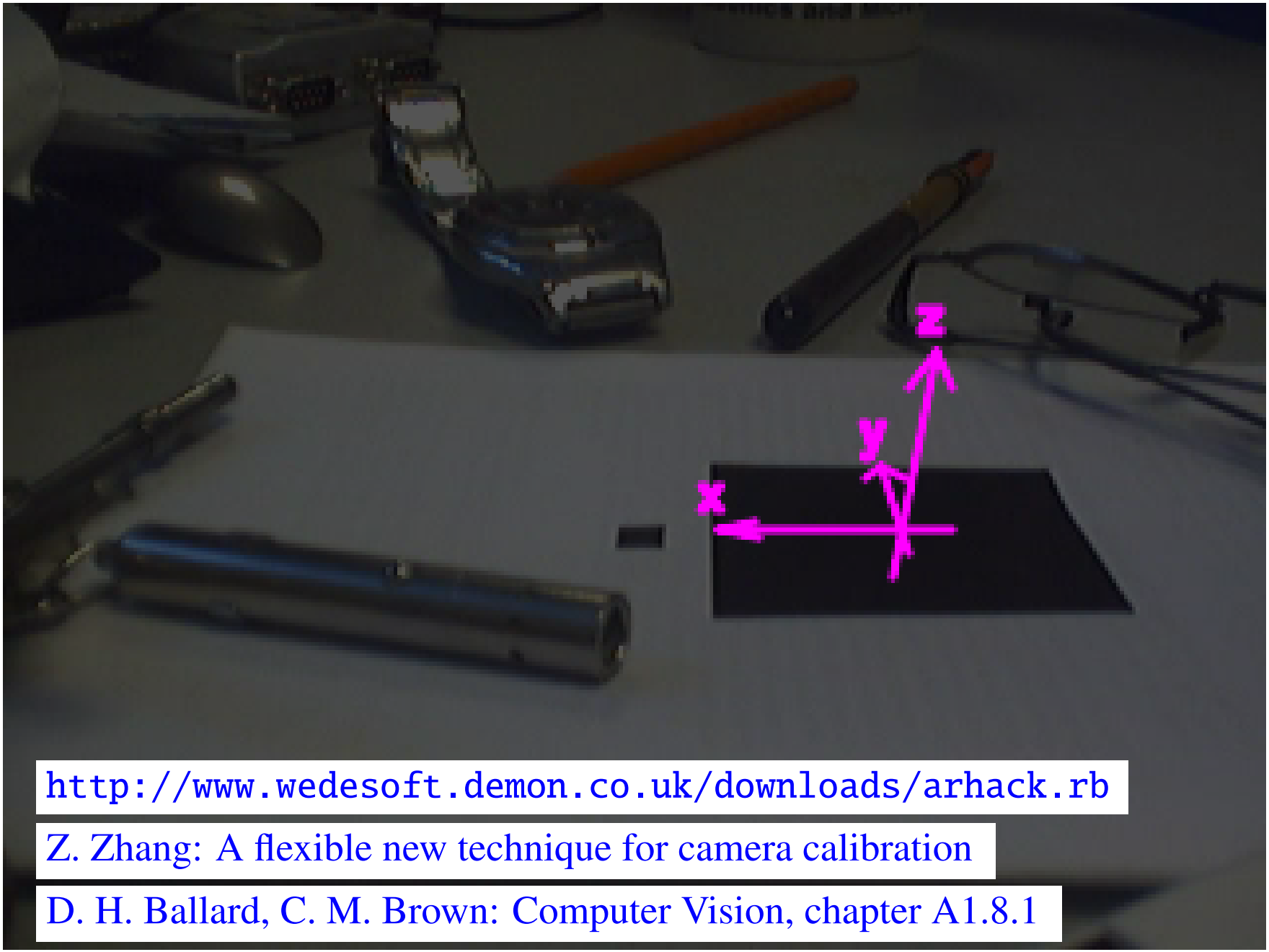
Augmented Reality Example

Source Code

```
constraints = []
for i in 0 ... 4 do
  constraints.push [ m[i].real, m[i].imag, 1.0, 0.0, 0.0, 0.0,
    -ms[i].real * m[i].real, -ms[i].real * m[i].imag, -ms[i].real ]
  constraints.push [ 0.0, 0.0, 0.0, m[i].real, m[i].imag, 1.0,
    -ms[i].imag * m[i].real, -ms[i].imag * m[i].imag, -ms[i].imag ]
end
h = Matrix[ *constraints ].svd[ 2 ].row( 8 ).reshape 3, 3
fs = 1.2 * 320 # focal length divided by pixel size
intr = Matrix[ [ fs, 0.0, 0.0 ], [ 0.0, fs, 0.0 ], [ 0.0, 0.0, 1.0 ] ]
rt = intr.inv * h
scale = 0.5 * ( rt.column( 0 ).norm + rt.column( 1 ).norm )
t = rt.column( 2 ) / scale
e1, e2 = rt.column( 0 ).normalise, e2 = rt.column( 1 ).normalise
e3 = e1.x e2
e1, e2, e3 = -e2, e1, -e3 if e3.inner_product( t ) > 0
extr = Matrix[ [ e1[0], e2[0], e3[0], t[0] ], [ e1[1], e2[1], e3[1], t[1] ],
               [ e1[2], e2[2], e3[2], t[2] ], [   0.0,   0.0,   0.0,  1.0 ] ]
```

Augmented Reality Example

Result



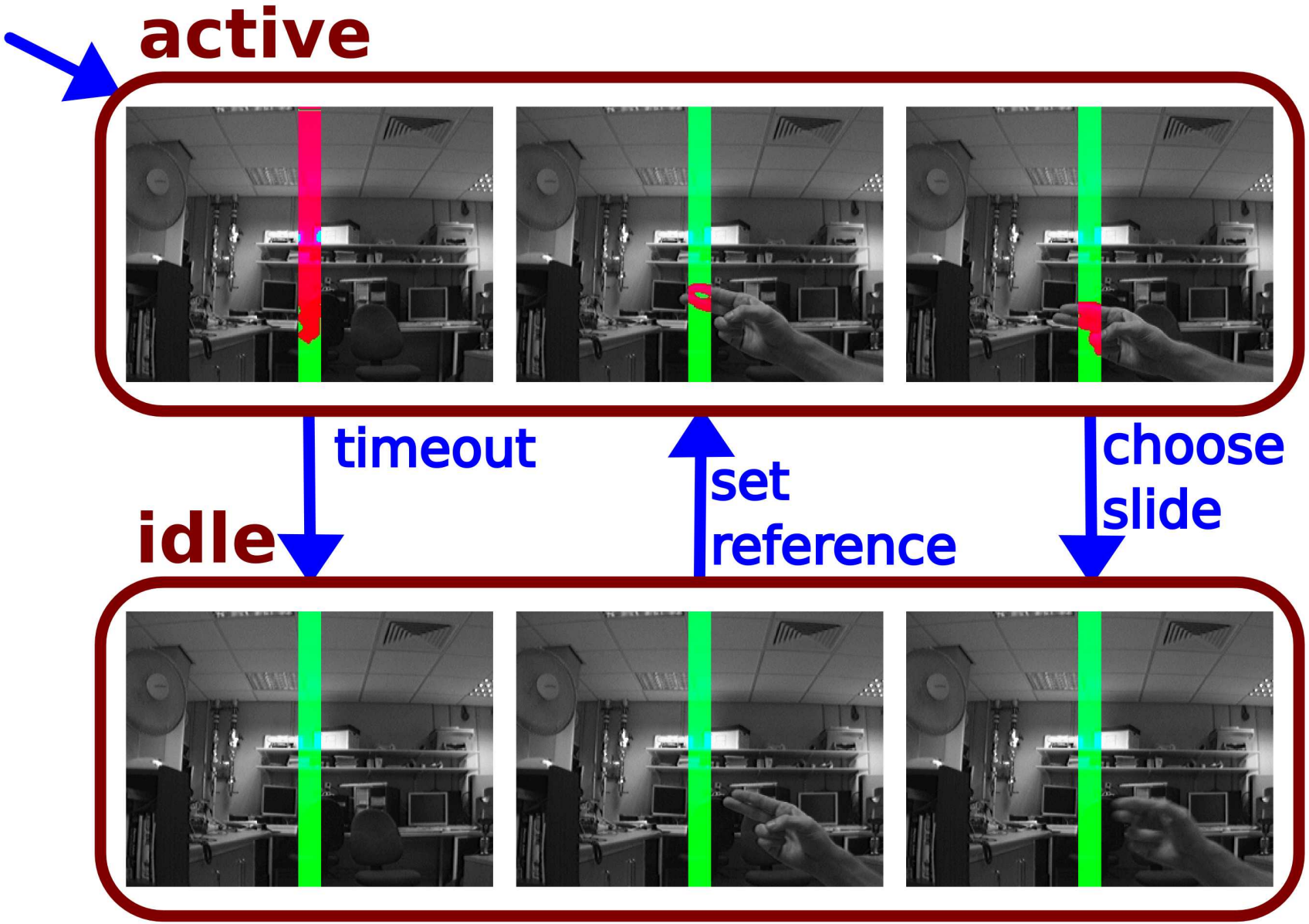
http://www.wedesoft.demon.co.uk/downloads/arhack.rb

Z. Zhang: A flexible new technique for camera calibration

D. H. Ballard, C. M. Brown: Computer Vision, chapter A1.8.1

Presenter

States



http://www.wedesoft.demon.co.uk/downloads/sensor.rb

Hornets Eye

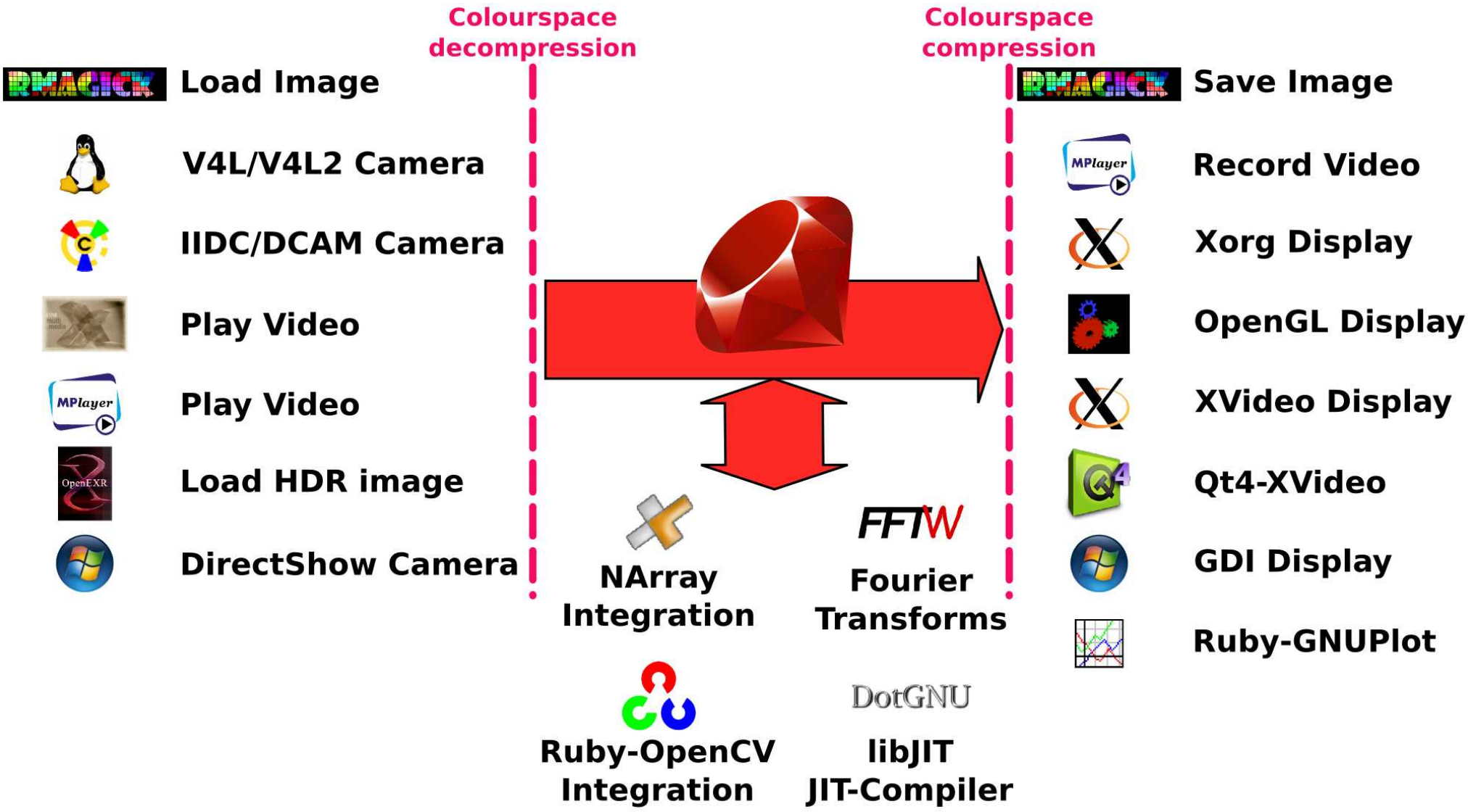
Presenter

Source Code (simplified)

```
input = DC1394Input.new
w, h, o = 20, input.height, input.width / 2 - 10
box = [ o ... o + w, 0 ... h ]
15.times { input.read }; bg = input.read_ubyte[ *box ]
ramp = Sequence.int( h ).indgen!.repmat( w ).roll
X11Display.show do
  img = input.read_ubytergb
  slice = ( img[ *box ].to_sint - bg ).gauss_blur( 2 ).abs >= 12
  n = slice.to_ubyte.sum
  if n > 20
    y = ramp.mask( slice ).sum / n
    print "#{ "%4d" % y }\r"; STDOUT.flush
  end
  img[ *box ].r = slice.to_ubyte * 255
  img[ *box ].g = slice.not.to_ubyte * 255
  img
end
```

Hornets Eye

Input/Output



Closures

Python + OpenCV

```
import sys
from opencv import cv
from opencv import highgui
highgui.cvNamedWindow( 'Camera' )
capture = highgui.cvCreateCameraCapture( -1 )
while 1:
    frame = highgui.cvQueryFrame( capture )
    gray = cv.cvCreateImage( cv.cvSize( frame.width, frame.height), 8, 1 )
    cv.cvCvtColor( frame, gray, cv.CV_BGR2GRAY )
    highgui.cvShowImage( 'Camera', gray )
    if highgui.cvWaitKey( 5 ) > 0:
        break
```

Ruby + HornetsEye

```
require 'hornetseye'
include Hornetseye
capture = V4L2Input.new
X11Display.show( :title => 'Camera' ) { capture.read.to_ubyte }
```

Colourspace Conversions

Y

$Y + C_r$

$Y + C_b$

$Y + C_r + C_b$

	Channel	Resolution
Y	Luminance	high
C_r	Chroma red	low
C_b	Chroma blue	low

See also: http://fourcc.org/

$$\begin{pmatrix} Y \\ C_b \\ C_r \end{pmatrix} = \begin{pmatrix} 0.299 & 0.587 & 0.114 \\ -0.168736 & -0.331264 & 0.500 \\ 0.500 & -0.418688 & -0.081312 \end{pmatrix} \begin{pmatrix} R \\ G \\ B \end{pmatrix} + \begin{pmatrix} 0 \\ 128 \\ 128 \end{pmatrix}$$

Lazy Computation

```ruby
class Seq
  def Seq.new( *arr )
    unless Thread.current[ :lazy ]
      super *arr
    else
      Lazy.new( *arr ) { |x| x }
    end
  end
  def initialize( *arr )
    @arr = arr
  end
  def -@
    Seq.new *@arr.collect { |x| -x }
  end
end
```

```ruby
class Lazy
  def initialize( *arr, &p )
    @arr, @p = arr, p
  end
  def demand
    Seq.new *@arr.collect { |i| @p.call i }
  end
  def -@
    Lazy.new( *@arr ) { |i| -@p.call( i ) }
  end
end
def lazy
  previous = Thread.current[ :lazy ]
  Thread.current[ :lazy ] = true
  retval = yield
  Thread.current[ :lazy ] = previous
  retval.demand
end
```

Credits

Credits

Aiden Lockwood, Aleksey Demakov, Annemie Wedekind, Balasundram Amavasai, Beverly Inkson, Chinwe Lucy Ozoegwu, Damien Douxchamps, Daniel Martín Marín, Géraud De La Mensbruge, Gerhard Wedekind, Hussein Abdul-Rahman, Jing Jing Wang, Jon Travis, Jong Peng, Juan Roldan, Julien Demarest, Julien Faucher, Julien Lacheray, Ken Dutton, Kim Chuan Lim, Kirill Kononenko, Klaus Treichel, Manuel Boissenin, Martin Howarth, Matthias Stumpf, Michael Doronin, Ralph Gay, Richard Dale, Sonia Fernández Rodríguez, Tan Kang Song, Ushakiran Soutapalli, Volkan Karaca, Warren Jasper, Zineb Saghi, ...

http://www.wedesoft.demon.co.uk/hornetseye-api/

http://rubyforge.org/projects/hornetseye/

http://sourceforge.net/projects/hornetseye/

http://launchpad.net/hornetseye/

http://raa.ruby-lang.org/project/hornetseye/

http://www.ohloh.net/p/hornetseye/